

## CLAIMS

1. An industrial robot for moving an object in space comprising a stationary platform (3), a movable platform (31) adapted for supporting the object, and a first (A), a second (B) and a third (C) arm to which the platforms are joined, wherein the first arm comprises a first actuator (10), a first supporting arm (13) influenced by the first actuator and rotatable around a first axis, and a first linkage (16, 17), the second arm comprises a second actuator (11), a second supporting arm (14) influenced by the second actuator and rotatable around a second axis, and a second linkage (18, 19), and the third arm comprises a third actuator (12), a third supporting arm (15) influenced by the third actuator and rotatable around a third axis, and a third linkage (20, 21), **characterized** in that the first and third axes are arranged parallel and that the second supporting arm is freely journalled around a transverse axis that is substantially arranged in a plane normal to the second axis.
2. An industrial robot according to claim 1, **characterized** in that the second supporting arm comprises a bearing (12A) and is adapted to rotate in a plane intersecting the movable platform.
3. An industrial robot according to claim 1 or 2, **characterized** in that the first and third linkages comprise a triangle with the base journalled in the respective supporting arm.
4. An industrial robot according any of the preceding claims, **characterized** in that the third linkage comprises a triangle where the base is journalled in the movable platform.

5. An industrial robot according claims 1 to 3,  
**characterized** in that the third linkage comprises a locked  
double link.

5 6. An industrial robot for moving an object in space com-  
prising a stationary platform, a movable platform adapted  
for supporting the object, and a first, a second and a  
third arm to which the platforms are joined, wherein the  
first arm comprises a first actuator, a first supporting  
10 arm influenced by the first actuator and displaceable along  
a first path, and a first linkage, the second arm comprises  
a second actuator, a second supporting arm influenced by  
the second actuator and displaceable along a second path,  
and a second linkage, and the third arm comprises a third  
15 actuator, a third supporting arm influenced by the third  
actuator and displaceable along a third path, and a third  
linkage, **characterized** in that the first and third paths  
are arranged parallel and that the second supporting arm is  
freely journaled around a transverse axis that is substan-  
20 tially arranged at right angles to the second path.

7. A method for manufacturing an industrial robot, with  
which an object is moved in space, comprising providing the  
industrial robot with a stationary platform, a movable  
25 platform adapted for supporting the object, and a first, a  
second and a third arm to which the platforms are joined,  
wherein the first arm is brought to comprise a first actu-  
ator, a first supporting arm influenced by the first actu-  
ator and rotatable around a first axis, and a first link-  
30 age, the second arm is brought to comprise a second actua-  
tor, a second supporting arm influenced by the second ac-  
tuator and rotatable around a second axis, and a second  
linkage, and the third arm is brought to comprise a third  
actuator, a third supporting arm influenced by the third  
35 actuator and rotatable around a third axis, and a third  
linkage, **characterized** in that the first and third axes are  
arranged parallel and that the second supporting arm is

arranged freely journalled around a transverse axis that is substantially arranged at right angles to the second axis.

8. Use of an industrial robot according to claims 1-6, or a  
5 method according to claim 7 during laser cutting.